

IN THE CLAIMS:

Please amend claims 1-7 as follows.

1. (Currently Amended) A leg type mobile robot comprising:

a body;

legs each connected to the body via a first joint; and

feet, each connected to an end part of the leg via a second joint, wherein each foot includes

at least one foot portion, which has a ground area to be grounded on a floor surface at ~~the a~~ bottom thereof, and

a floor reaction force detector ~~for detecting~~ configured to detect a floor reaction force acting from a floor surface through the foot portion, and wherein

a center (~~P_e~~) of the second joint is offset against a position ~~P_a~~ in a plane view,

the position ~~P_a~~ is the position where ~~the a~~ distance to ~~the a~~ remotest point of at least one ground area becomes minimum, and

a center (~~P_b~~) of the floor reaction force detector is ~~provided so that the center P_b is in the vicinity of~~ closer to the position ~~P_a~~ than to the center ~~P_e~~ of the ~~ankle~~ second joint in a plane view.

2. (Currently Amended) A leg type mobile robot according to claim 1, wherein

the center (~~P_b~~) of the floor reaction force detector is offset to a rear direction with respect to the position (~~P_a~~).

3. (Currently Amended) A leg type mobile robot according to claim 2, wherein the center (~~Pb~~) of the floor reaction force detector is positioned on a line segment connecting the position (~~Pa~~) and the center (~~Pe~~) of the second joint.

4. (Currently Amended) A leg type mobile robot according to claim 1, wherein the center (~~Pb~~) of the floor reaction force detector is offset to a rear direction in a center side of the leg type mobile robot with respect to the position (~~Pa~~).

5. (Currently Amended) A leg type mobile robot according to claim 4, wherein the center (~~Pb~~) of the floor reaction force detector is located on the perpendicular taken down from the center (~~Pe~~) of the second joint to the line segment extended from the position (~~Pa~~) to a rear direction.

6. (Currently Amended) A leg type mobile robot according to claim 4, wherein the center (~~Pb~~) of the floor reaction force detector is located on the perpendicular taken down from the center (~~Pe~~) of the second joint to the line segment extended from the position (~~Pa~~) to a center of the leg type mobile robot.

7. (Currently Amended) A leg type mobile robot according to claim 4, wherein

the center (~~Pb~~) of the floor reaction force detector is positioned on a line segment connecting the position (~~Pa~~) and the center (~~Pe~~) of the second joint.